

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	645	318/568.12.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:10
L2	4	1 and stereo near4 camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:17
L3	974	324/758.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:23
L4	636	318/580.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:17
L5	1	3 and stereo near4 camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:18
L6	1	4 and stereo near4 camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:17
L7	7	1 and stereo with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:26
L8	1	3 and stereo with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:18
L9	1	3 and stereo with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:18

L10	758	robot with (surface or ground or area or plane or floor) and (robot or camera) with (calibrat\$3 or diagnos\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:20
L11	6	4 and 10	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:21
L12	44	pad same (robot or camera) and robot with (surface or ground or area or plane or floor) and (robot or camera) with (calibrat\$3 or diagnos\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:23
L13	1	3 and 12	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:23
L14	41	indicat\$3 with (position or location) with robot with (floor or plane or surface or area) and (robot with camera)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:24
L15	3	1 and 14	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:25
L16	1252	700/245.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:25
L18	1291	704/275.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:26
L19	111	348/139.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:26

L20	25	16 and stereo with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:27
L21	3	18 and stereo with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:27
L22	13	19 and stereo with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:28
S1	2458	stereo near4 camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/28 07:09
S2	861	702/150.ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 10:55
S3	4	S1 and S2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 10:58
S4	18787	(surface or platform or support or plane or plate or stage) with (flat or level or horizontal\$3) same camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 13:25
S5	5269	(surface or platform or support or plane or plate or stage) with (flat or level or horizontal\$3) with camera with (dispos\$3 or position\$3 or locat\$3 or provid\$3 or mount\$3 or install\$3 or plac\$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 11:47
S6	11455	(surface or platform or support or plane or plate or stage) with (camera or robot) with (position\$2 or relation\$4) with (display\$3 or indicat\$3 or determin\$3 or detect\$3 or measur\$5 or obtain\$3 or generat\$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 13:55

S7	1360	S5 and S6	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 11:54
S8	149	S7 and (diagnos\$3 or calibrat\$3) with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 11:55
S9	204	S7 and (diagnos\$3 or calibrat\$3 or test\$3) with camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 13:27
S10	16	S9 and robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 11:55
S11	0	("2005/0237385").URPN.	USPAT	OR	OFF	2005/11/23 11:56
S12	17369	(surface or platform or support or plane or plate or stage) with (flat or level or horizontal\$3 or base or mat) with (texture or mark or code)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 13:48
S13	4	S12 and (diagnos\$3 or calibrat\$3) with camera same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 13:50
S14	591554	(surface or platform or support or plane or plate or stage) with (flat or level or horizontal\$3 or base or mat) same (texture or mark or code or point or coordinate)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:13
S15	492	S14 and camera with robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 13:50
S16	105	S15 and camera with (calibrat\$3 or diagnos\$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:14

S17	4	S16 and (surface or platform or support or plane or plate or stage or base) with (robot) with (position\$2 or relation\$4) with (display\$3 or indicat\$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 15:15
S18	15	("4969735" "4979815" "5040116" "5109345" "5109425" "5130794" "5168141" "5175616" "5216476" "5320538" "5331413" "5420828" "5495576" "5510625" "5526022").PN.	US-PGPUB; USPAT; USOCR	OR	OFF	2005/11/23 14:07
S19	6	("5684531").URPN.	USPAT	OR	OFF	2005/11/23 14:08
S20	1	S19 and robot with (location or position\$2 or coordinate)	USPAT	OR	ON	2005/11/23 14:09
S21	1	S19 and robot with camera	USPAT	OR	ON	2005/11/23 15:14
S22	6253	(surface or platform or support or plane or plate or stage or base or ground or mat) with (texture or mark or code or point or coordinate) same (robot or robot\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:37
S23	382	S22 and robot with camera	USPAT	OR	ON	2005/11/23 15:38
S24	72	S23 and camera with (calibrat\$3 or diagnos\$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:40
S25	5	S24 and (surface or platform or support or plane or plate or stage or base or mat) with robot with (position\$2 or relation\$4) with (display\$3 or indicat\$3 or output\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 15:43
S26	59528	(surface or platform or support or plane or plate or stage or base or ground or mat) same (robot or robot\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:59
S27	1093	S26 and robot with camera	USPAT	OR	ON	2005/11/23 15:52
S28	135	S27 and camera with (calibrat\$3 or diagnos\$3)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:40
S29	7	S28 and (surface or platform or support or plane or plate or stage or base or mat) with robot with (position\$2 or relation\$4) with (display\$3 or indicat\$3 or output\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 15:52

S30	4033	(floor) same (robot or robot\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 15:52
S31	187	S30 and robot with camera	USPAT	OR	ON	2005/11/23 16:00
S32	0	S31 and (sfloor) with robot with (position\$2 or relation\$4) with (display\$3 or indicat\$3 or output\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 15:52
S33	8	S31 and (floor) with robot with (position\$2 or relation\$4) with (display\$3 or indicat\$3 or output\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/23 15:52
S34	60554	(surface or platform or support or plane or plate or stage or base or ground or mat or floor) same (robot or robot\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:06
S35	1118	S34 and robot with camera	USPAT	OR	ON	2005/11/23 16:15
S36	6	S35 and (robot or camera) same folding	USPAT	OR	ON	2005/11/23 16:02
S37	13	S35 and (robot or camera) same (folding or folded)	USPAT	OR	ON	2005/11/23 16:05
S38	3876	template near4 match\$3	USPAT	OR	ON	2005/11/23 16:05
S39	20	S38 and epipolar adj line\$1	USPAT	OR	ON	2005/11/23 16:06
S40	19	S39 and (surface or platform or support or plane or plate or stage or base or ground or mat or floor) with (texture or mark or point or coordinate or label or code)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:09
S41	3	S39 and (surface or platform or support or plane or plate or stage or base or ground or mat or floor) with (texture or mark or point or coordinate or label or code) with template	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:07
S42	4	S40 and (robot same camera)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:12
S43	0	mattern\$1 with shaded with uniform	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:12

S44	0	mattern\$1 with shaded with uniform\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:13
S45	0	mattern\$1 with shaded	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:13
S46	58	pattern\$1 with shaded with uniform\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:14
S47	1	S46 same surface with texture	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:14
S48	69289	pattern\$1 with (shaded or uniform\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:14
S49	328	S48 same surface with texture	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:15
S50	328	S48 same (surface or floor) with texture	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/23 16:15
S51	1	S50 and robot with camera	USPAT	OR	ON	2005/11/23 16:16
S52	28	S48 and robot with camera	USPAT	OR	ON	2005/11/23 16:16
S53	0	S52 and calibrat\$3 same geometrical with (pattern or shape)	USPAT	OR	ON	2005/11/23 16:17
S54	2	S52 and calibrat\$3 and geometrical with (pattern or shape)	USPAT	OR	ON	2005/11/23 16:17
S55	2	"5684531".pn.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	OFF	2005/11/25 09:00

S56	191	indicat\$3 with (position or location) with robot with (floor or plane or surface or area)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:24
S57	41	S56 and (robot with camera)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:00
S58	1397	mat same (robot or camera)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:06
S59	58	S58 and robot with (surface or ground or area or plane or floor)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:06
S60	2	S59 and mat with fold\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:03
S61	5	S59 and (robot or camera) with (calibrat\$3 or diagnos\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:07
S62	9064	pad same (robot or camera)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:22
S63	721	S62 and robot with (surface or ground or area or plane or floor)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:53
S64	44	S63 and (robot or camera) with (calibrat\$3 or diagnos\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:54
S65	0	("2004/0249504").URPN.	USPAT	OR	OFF	2005/11/25 11:52

S66	0	S64 and shaded with pattern	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:54
S67	1180	robot with (surface or ground or area or plane or floor) same camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:57
S68	195	S67 and (robot or camera) with (calibrat\$3 or diagnos\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:58
S69	1	S68 and shaded with pattern	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:55
S70	5	S68 and shaded	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:58
S71	19197	robot with (surface or ground or area or plane or floor)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:20
S72	758	S71 and (robot or camera) with (calibrat\$3 or diagnos\$4)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/28 07:19
S73	22	S72 and shaded	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT ; IBM_TDB	OR	ON	2005/11/25 11:58